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REPORT DOCUMENTATION PAGE

Form Approved
OMB No. 0704-0188

AD-A204 638

2b. DECLASSIFICATION/DOWNGRADING SCHEDULE		1b. RESTRICTIVE MARKINGS	
4. PERFORMING ORGANIZATION REPORT NUMBER(S)		3. DISTRIBUTION/AVAILABILITY OF REPORT Approved for public release; distribution unlimited.	
5. MONITORING ORGANIZATION REPORT NUMBER(S) AFOSR-TR- 89-0024		6a. NAME OF PERFORMING ORGANIZATION Boston University College of Engineering	
6b. OFFICE SYMBOL (If applicable)		7a. NAME OF MONITORING ORGANIZATION AFOSR /NM	
6c. ADDRESS (City, State, and ZIP Code) 44 Cummington Street Boston, Massachusetts 02215		7b. ADDRESS (City, State, and ZIP Code) Building 410 Bolling, AFB DC 20332-6448	
8a. NAME OF FUNDING/SPONSORING ORGANIZATION AFOSR		8b. OFFICE SYMBOL (If applicable) NM	
9. PROCUREMENT INSTRUMENT IDENTIFICATION NUMBER AFOSR-87-0213		10. SOURCE OF FUNDING NUMBERS	
10c. ADDRESS (City, State, and ZIP Code) Building 410 Bolling, AFB DC 20332-6448		PROGRAM ELEMENT NO. 61102F	PROJECT NO. 2304
11. TITLE (Include Security Classification) MODULAR PROCESSING STAGES OF THE PIPE MACHINE		TASK NO. A2	WORK UNIT ACCESSION NO.
12. PERSONAL AUTHOR(S) Allen Waxman			
13a. TYPE OF REPORT FINAL	13b. TIME COVERED FROM 1 May 87 TO 30 Apr 88	14. DATE OF REPORT (Year, Month, Day) June 30, 1988	15. PAGE COUNT 2
16. SUPPLEMENTARY NOTATION			
17. COSATI CODES		18. SUBJECT TERMS (Continue on reverse if necessary and identify by block number)	
FIELD	GROUP	SUB-GROUP	
19. ABSTRACT (Continue on reverse if necessary and identify by block number) These 4 stages, combined with the basic PIPE machine including 1 stage plus the ISMAP and support stages (acquired from the National Bureau of Standards), 1 stage purchased with grant funds from Digital Equipment Corp., and 2 stage still on loan from Aspex Inc.			
20. DISTRIBUTION/AVAILABILITY OF ABSTRACT <input type="checkbox"/> UNCLASSIFIED/UNLIMITED <input type="checkbox"/> SAME AS RPT. <input type="checkbox"/> DTIC USERS		21. ABSTRACT SECURITY CLASSIFICATION UNCLASS	
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June 30, 1988

re: Final report on Award No. AFOSR-87-0213
"Modular Processing Stages of the PIPE Machine"

This grant, for \$52,000 was applied entirely for the purchase of:

4 Modular Processing Stages for PIPE (frame buffers expanded 4X-deep),	\$53,200
- other funds used for this purchase	- 1,200
Net cost	\$52,000

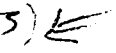
Purchased from Aspex Inc. of New York, NY (formerly Digital/Analog Design Associates).

These 4 stages, combined with the basic PIPE machine including 1 stage plus the ISMAP and support stages (acquired from the National Bureau of Standards), 1 stage purchased with grant funds from Digital Equipment Corp., and 2 stages still on loan from Aspex Inc. (I still owe them \$35,000, gave us a complete PIPE machine by November 1987.

The PIPE machine has played a very significant role in our research at the Laboratory for Sensory Robotics. Since November 1987 we have developed real-time PIPE algorithms for the following vision tasks:

1. basic feature extraction such as edges, zero-crossings, gradients, orientations, corners, change detection, log-polar transforms;
2. moving object centroid detection and tracking for a binocular robot eye motion system under neural control (using ADALINES);

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3. measurement of visual motion (for moving edges) based on the theory of Convected Activation Profiles by Waxman et al.; image velocity fields are updated at 15 times per second;
4. stereo vision matching based on Prazdny's disparity gradient limit "local support" algorithm with depth maps generated once per second;
5. preliminary implementation on PIPE of perceptual grouping of features using the Neural Analog Diffusion-Enhancement Layer (NADEL) concept of Waxman & Seibert. (JES) 
6. developed a strategy to implement 16-bit additions, multiplications, and convolutions on the 8-bit PIPE machine;
7. beginning a study of Adaptive Associative Memories on PIPE.

Application #5 is very new and extremely exciting. This neural network is useful for a large number of early vision tasks, and simulations which require about 2 hours on a SUN-3 will require only 10 seconds on PIPE. A detailed parametric study of the NADEL, and its implementation on PIPE is the subject of my recent proposal to AFOSR, Life Sciences Division, entitled: "Parametric Study of Diffusion-Enhancement Networks for Spatio-Temporal Grouping in Real-Time Artificial Vision."

The following publications discuss our work on PIPE:

1. "Progress on the Prototype PIPE" by R. Goldenberg, W.C. Lau, A. She & A.M. Waxman. *Proceed. IEEE 1987 Conf. Robotics & Automation*, Raleigh, NC, pp. 1267-1274, (1987).
2. "Convected Activation Profiles and the Measurement of Visual Motion" by A.M. Waxman, J. Wu & F. Bergholm. *Proceed. IEEE 1988 Conf. Computer Vision and Pattern Recognition*, Ann Arbor, MI, pp. 717-723, (1988). Extended version submitted to the 1988 Int'l. Conf. on Computer Vision.
3. "Spreading Activation Layers, Visual Saccades, and Invariant Representations for Neural Pattern Recognition Systems" by M. Seibert & A.M. Waxman. *Neural Networks*, in press (1988).
4. "Visual Motion in the Short and the Long: From Receptive Fields to Neural Networks" by A.M. Waxman, J. Wu & M. Seibert. Submitted to the *IEEE 1989 Workshop on Visual Motion*, Irvine, CA (March 1989).

Sincerely yours,



Allen Waxman
Associate Professor

